

EAST Search History

EAST Search History (Prior Art)

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	0	unsufficient near0 cpatured near0 image	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:36
L2	0	unsufficient near0 captured near0 image	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:36
L3	0	unsufficient same captured near0 image	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:37

L4	82153	captured near0 image	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:37
L5	75658	movable near0 portion	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:37
L6	429	4 and 5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:38
L7	184142	location and insufficient	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:38

L8	82	6 and 7	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:38
L9	259484	robot\$6	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:39
L10	9	8 and 9	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/12/04 08:39
S1	0	digital near0 cameara and extrinsic near0 parameters	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:46

S2	0	cameara and extrinsic near0 parameters	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:47
S3	670	extrinsic near0 parameters	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:47
S4	494	extrinsic near0 parameters and camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:47
S5	249	extrinsic near0 parameters and camera and image near10 calibration	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/23 19:48

S6	56	extrinsic near0 parameters and camera and image near10 calibration near0 object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 12:44
S7	4102	robot and manipulate and scal\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 13:04
S8	6	extrinsic near0 parameters and camera and image near10 calibration near0 object and S7	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 13:05
S9	56	extrinsic near0 parameters and camera and image near10 calibration near0 object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 14:54

S10	1917	robot and manipulate and scal\$3 and sample and features	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 14:56
S11	152	robot and manipulate and scal\$3 and sample and features and reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 15:01
S12	34	robot same manipulate and scal\$3 and sample and features and reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 15:32
S13	31	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 15:39

S14	24	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 16:15
S15	16	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame and six	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 16:20
S16	6	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulat\$3 and frame and six and camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 17:09

S17	6	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulats\$3 and frame and six and camera and position and frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 17:18
S18	6	robot same manipulate and scal\$3 and sample and features and reference near0 frame and image and select\$3 and object and robot and manipulats\$3 and frame and six and camera and position and frame and computer	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 17:48

S19	8168	(700/245 1700/246 1700/253 1700/257 1700/258 1700/259 1700/279 or 29/218 129/702 129/714 129/720 129/407.1 129/407.04 or 318/568.13 I 318/568.15 1318/568.16 1318/640 or 348/42 1348/94 1348/154 1348/1901 348/291 1348/287552 or 901/6 1901/14 1901/17 1901/46 1901/47 or 414/730 1414/737 or 382/154). ccls.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 20:52
S20	117	("4871252" or "5999881" or "4949277" or "4980762" or "5016110" or "5177563" or "5295778" or "5300869" or H001378 or "5696674" or "5819304" or "5870303" or	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/24 20:54

"6081370" or
"6096999" or
"4273505" or
"4299386" or
"4307891" or
"4312432" or
"4359815" or
"4421450" or
"4479754" or
"4479717" or
"4480170" or
"4484855" or
"4488173" or
"4494874" or
"4502830" or
"4556360" or
"4568238" or
"4574655" or
"4576537" or
"4582277" or
"4594001" or
"4624621" or
"4627511" or
"4762459" or
"4764077" or
"4779804" or
"4782567" or
"4783904" or
"4789417" or

		"4815901" or "4818858" or "4865514" or "4875273" or "4875823" or "4886375" or "4934504" or "4942539" or "4943889").pn.				
S21	961	camera and orthogonal near0 axes and rotation and translation	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:53
S22	171	camera and orthogonal near0 axes and rotation and translation and reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:53
S23	0	camera and orthogonal near0 axes and rotation and translation and reference near0 frame and space near6 training	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:54

S24	23	camera and orthogonal near0 axes and rotation and translation and reference near0 frame and space and training	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 08:54
S25	209	scale near0 factor and framegrabber	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:11
S26	2	scale near0 factor same framegrabber	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:11
S27	2	scale near0 factor same framegrabber and resampling	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:12

S28	0	scale near0 factor same framegrabber and sampling	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:12
S29	2	scale near0 factor same framegrabber and focal near0 length	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:13
S30	2	scale near0 factor same framegrabber and camera	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:13
S31	2	scale near0 factor same framegrabber and lens	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:13

S32	2	scale near0 factor same framegrabber and distortion	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:14
S33	354	object near0 space near0 coordinate	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:51
S34	3	object near0 space near0 coordinate and select\$3 near0 feature	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:52
S35	60	object near0 space near0 coordinate and image and teaching	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 10:53

S36	30	object near0 space near0 coordinate and select\$3 near10 image and teaching	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 11:00
S38	0	robot same mov\$3 near3 camera near0 orthogonally	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:39
S39	1	robot same mov\$3 near10 camera near0 orthogonally	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:39
S40	0	robot same mov10 near10 camera near0 orthogonally	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:39

S41	0	robot same orient\$3 near10 camera near0 orthogonally	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:40
S42	0	robot same camera near0 orthogonally	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:40
S43	24	camera near0 orthogonally	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:41
S44	0	camera near0 orthogonally and robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 12:41

S45	2	camera and object near0 space near0 reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:05
S46	80	camera and object near6 space near10 reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:06
S47	56	camera and object near6 space near5 reference near0 frame	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:06
S48	0	("20020159628" "4,942,539" "5,802,201" "20040233461" "20100040255" "20010034481").pn. and position near3 orientation and tool near0 frame near0 reference and	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:58

		transformations				
S49	13	position near3 orientation and tool near0 frame near0 reference and transformations	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:58
S50	12	position near3 orientation and tool near0 frame near0 reference and transformations and object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 22:59
S51	2	"20100231706".pn.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 23:15
S52	1	"20100231706".pn. and tool	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/25 23:15

S53	0	adjusting same robot same insufficient and image and target near0 object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:04
S54	2	adjusting same robot same insufficient and image and target and object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:04
S55	2	adjusting same robot same insufficient and image	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:05
S56	139	adjusting same robot and insufficient and image	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:06

S57	104	adjusting same robot and insufficient and image and target	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:06
S58	103	adjusting same robot and insufficient and image and target and object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 00:06
S59	12	("20020159628" "4,942,539" "5,802,201" "20040233461" "20100040255" "20010034481").pn.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:06
S60	317	pose near0 estimation and three near2 dimensional and two near2 dimensional	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:22

S61	40	pose near0 estimation and three near2 dimensional and two near2 dimensional and target near0 object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:23
S62	14	("20020159628" "4,942,539" "5,802,201" "20040233461" "20100040255" "20010034481" "4,729,536").pn.	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:54
S63	0	camera near0 mounted same movable same portion and robot near5 effector	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:58
S64	1	camera near0 mounted same movable same portion same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 10:59

S65	38	camera near0 mounted and movable same portion same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 11:00
S66	1	camera near3 mounted near5 orthogonally same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:54
S67	4	camera near6 orthogonally same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:55
S68	5	camera near10 orthogonally same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:55

S69	16	camera near10 orthogonally and robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 12:56
S70	14	camera same orthogonally same robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 13:02
S71	115	camera same orthogonally and robot	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 13:12
S72	27	adjusting near3 position same robot and insufficient and image and target and object	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2010/11/26 14:10

EAST Search History (Interference)

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12/4/10 8:42:38 AM

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